

WEST Search History

DATE: Sunday, March 22, 2009

<u>Hide?</u>	<u>Set Name</u>	<u>Query</u>	<u>Hit Count</u>
	<i>DB=USPT; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L94	foot and L93	17
<input type="checkbox"/>	L93	float\$4 and L92	18
<input type="checkbox"/>	L92	"0" and L91	71
<input type="checkbox"/>	L91	robot\$6 and L90	92
<input type="checkbox"/>	L90	L89 and zmp	92
<input type="checkbox"/>	L89	(700/245 700/246 700/251 700/253 700/260 700/261 318/568.1 318/568.12 318/568.16 318/568.17 318/568.2 901/1 901/9 901/46 180.1).ccls.	2246
<input type="checkbox"/>	L88	((("6962220"))!.PN.) .p67-p150.	1
	<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L87	robot\$6 and (walk\$3 or biped or humanoid or two legged) and (inlina\$6 or betn or tilt or deviat\$5 or obliqu\$5 or indirect\$4 or change direction or slope or slant)	6284
<input type="checkbox"/>	L86	('6711469' '6697709' '6567724' '6505098' '6493606' '6480761' '6330494' '6289265' '6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	16
<input type="checkbox"/>	L85	marc.xa. and legged and inclination	35
<input type="checkbox"/>	L84	marc.xa. and legged and inclinaiton	0
<input type="checkbox"/>	L83	('5404086')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L82	(edditng or updating) and (motion or traject\$4 or movement) and zmp and robot\$6	27
<input type="checkbox"/>	L81	(edditng or updating) same (motion or traject\$4 or movement) and zmp and robot\$6	12
<input type="checkbox"/>	L80	(edditng or updating) same (motion or traject\$4 or movement) and L79	10
<input type="checkbox"/>	L79	robot and zmp and yaw	169
<input type="checkbox"/>	L78	marc.xa. and zmp	47
<input type="checkbox"/>	L77	10/181500	3

<input type="checkbox"/>	L76	('6697709' 'l'6289265' 'l'6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	6
<input type="checkbox"/>	L75	marc.xa. and robot and zmp	47
<input type="checkbox"/>	L74	(motions or movement or displacement) and L73	122
<input type="checkbox"/>	L73	computer and L72	135
<input type="checkbox"/>	L72	record\$3 and L71	135
<input type="checkbox"/>	L71	(request or command) and L70	166
<input type="checkbox"/>	L70	L66 and L69	174
<input type="checkbox"/>	L69	execut\$5 and L68	312322
<input type="checkbox"/>	L68	run or L66	1389091
<input type="checkbox"/>	L67	(6458772 or 6284156 or 6348461 or 6262044 or 6410586 or 6342245 or 6277877 or 6399557 or 3857856 or 5835892 or 6376445 or 6440911 or 6163111 or 5610305 or 5230889 or 4391489 or 4483594 or 6410749 or 4876009 or 6358945 or 6281227 or 6391397 or 6432994 or 4920120 or 5874378 or 6374641 or 5384779 or 5523998 or 5537098 or 4260406 or 4293439 or 4386503 or 5179438 or 5208607 or 6275216 or 5534261 or 5640119 or 5831440 or 6049212 or 6271251 or 4949326 or 5015815 or 5194938 or 4870247 or 6258470 or 6316465 or 6388989 or 4505827 or 5210848 or 5230070).pn.	98
<input type="checkbox"/>	L66	(similar or "same") function and L65	201
<input type="checkbox"/>	L65	robot and control software and (chang\$3 or replac\$5)	2160
<input type="checkbox"/>	L64	('20050125099')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L63	(10/126774 10/970977 10/935607 10/919172 10/775845 10/732446 10/726597 10/683496 10/637890)	18
<input type="checkbox"/>	L62	(motion or displacement or trajector\$3) and L61	116
<input type="checkbox"/>	L61	(humanoid or two legged robot and human like robot) and zmp and comput\$5	119
<input type="checkbox"/>	L60	zmp and "approximately 0"	20
		<i>DB=PGPB,USPT; PLUR=YES; OP=ADJ</i>	
<input type="checkbox"/>	L59	((("20060106495")!.PN.).PGPB. ((("7119510")!.PN.).USPT.	2
		<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>	
<input type="checkbox"/>	L58	grasping and L57	6
<input type="checkbox"/>	L57	horizontal and vertical and L56	20
<input type="checkbox"/>	L56	signal and detection and L55	20
<input type="checkbox"/>	L55	distance and L54	23

<input type="checkbox"/>	L54	center and L53	28
<input type="checkbox"/>	L53	motion and L52	30
<input type="checkbox"/>	L52	gravity and L51	31
<input type="checkbox"/>	L51	floor reaction and L50	37
<input type="checkbox"/>	L50	foot and robot and ground contact and sensor and sole and joint and reaction and force and walk\$3	55
<i>DB=PGPB; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L49	L48	1
<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>			
<input type="checkbox"/>	L48	10/553278	1
<input type="checkbox"/>	L47	L46 and robot	13
<input type="checkbox"/>	L46	metatarsophalangeal	540
<input type="checkbox"/>	L45	ground and contact and L43	26
<input type="checkbox"/>	L44	groung and contact and L43	0
<input type="checkbox"/>	L43	sensor and L42	34
<input type="checkbox"/>	L42	axis and L41	34
<input type="checkbox"/>	L41	soles and L40	34
<input type="checkbox"/>	L40	foot and L39	39
<input type="checkbox"/>	L39	L38 and coordinate	39
<input type="checkbox"/>	L38	position and orientation and L37	44
<input type="checkbox"/>	L37	(L9 or L10) and L36	85
<input type="checkbox"/>	L36	landed and landing and foot and robot\$6	153
<input type="checkbox"/>	L35	landed and landing and foot and footstep and robot\$6	6
<input type="checkbox"/>	L34	landed and landing and foot and footstep and (L9 or L10)	3
<input type="checkbox"/>	L33	landded and landing and foot and footstep and (L9 or L10)	0
<input type="checkbox"/>	L32	landded and landing and foot and footstep and L23	0
<input type="checkbox"/>	L31	landded and landing and foot and L30	0
<input type="checkbox"/>	L30	posture and L29	52
<input type="checkbox"/>	L29	gravity and coordinate and L28	53
<input type="checkbox"/>	L28	estimat\$3 and position and L27	62
<input type="checkbox"/>	L27	dynamics same model and L24	74

<input type="checkbox"/>	L26	dyanamics and L24	0
<input type="checkbox"/>	L25	dyanamics same model and L24	0
<input type="checkbox"/>	L24	L22 and L23	184
<input type="checkbox"/>	L23	movement or trajectory and L22	2694961
<input type="checkbox"/>	L22	floor and zmp and L9	193
<input type="checkbox"/>	L21	floor and zmp and L20	0
<input type="checkbox"/>	L20	(5024920 5173382 5490103 5557564 5901829 6201488 6521838 6518503 6695663 6592418 5733819 6027554 6663326 6694847 6685863 4252414 4588518 4561746 4719331 5118090 5434926 5419740 5558196 5527940 5716481).pn.	47
<input type="checkbox"/>	L19	motion pattern and L17	2
<input type="checkbox"/>	L18	motion pattern and stor\$3 and L17	0
<input type="checkbox"/>	L17	freedom and L16	5
<input type="checkbox"/>	L16	L14 and L15	6
<input type="checkbox"/>	L15	L14 and gait or gate	1273890
<input type="checkbox"/>	L14	('6580969' 'l'6493606' 'l'6463356' 'l'6289265' 'l'6243623' 'l'5872893' 'l'5841258' 'l'5838130' 'l'5594644' 'l'EP 1136193A' 'l'EP 1103451A')!.ABPN1, NRPN,PN,TBAN,WKU.	18
<input type="checkbox"/>	L13	('20030019671' 'l'20020138359' 'l'6591923' 'l'6458011')!.ABPN1,NRPN,PN, TBAN,WKU.	7
<input type="checkbox"/>	L12	(legged robot or pet robot or humanoid near10 robot) motion and pattern	13
<input type="checkbox"/>	L11	(legged robot or pet robot or humanoid near10 robot) motion and pattern and L10	0
<input type="checkbox"/>	L10	(6252544 6493606 6243623 6289265 5673367 5355064 5455497 5325031 5357433 5594644 6580969 6718231 5504841 5842533 4621333 4633059 4987527 5937398 6064168 6429812 6584377 5259064 5349646 5946041 4540211 4762261 5273296 5616917 5627440 5794621 6059092 6059092 6068201 6456728 6505098 6711469 5402050 5525883 5841258 6463356 4614504 5040626 5343397 5369346 5378969 5644204 5672924 5838130 5872893 6229552).pn. (700/245 700/246 700/251 700/253 700/260 700/261 or 318/568.1 318/568.12 318/568.16 318/568.17 318/568.2 or 901/1 901/9 901/46 or 180/8.1 180/8.6 180/65.1 or 701/23 or 320/116 320/120 or 446/376 446/384).ccls.	97
<input type="checkbox"/>	L9		10678
<input type="checkbox"/>	L8	6580969.pn.	2

<input type="checkbox"/>	L7	11/456454	2
<input type="checkbox"/>	L6	10/511608	1
<input type="checkbox"/>	L5	coordinate and L4	7
<input type="checkbox"/>	L4	"foot-sole" and L2	22
<input type="checkbox"/>	L3	"based on" and L2	48
<input type="checkbox"/>	L2	foot same position same sole	4883
<input type="checkbox"/>	L1	takenaka.in. and floor reaction force and position	102

END OF SEARCH HISTORY